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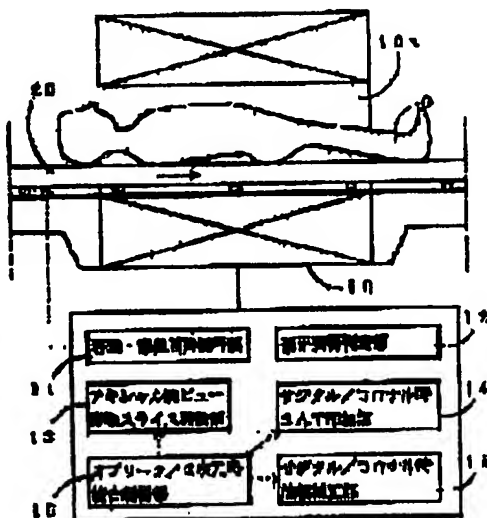
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(54) IMAGE PICKUP DEVICE USING MRI DEVICE

(57)Abstract:

PURPOSE: To pick up an image by the MRI device while successively shifting an examinee.

CONSTITUTION: A section 11 which executes the movement and the image pickup at the same time controls a belt conveyor 20 at the speed  $G_v$  smaller than or equal to the  $(M_w - G_w)/M_t$ , (where, the length in the movement direction of the image pickup range of an MRI device 10 is taken as  $M_w$ , the length in the movement direction at the image pickup range as  $G_w$ , and the time required to collect one image of data as  $M_t$ ), and the movement by the belt conveyor 20 and the image pickup by the MRI device 10 are executed at the same time. Thus, the efficiency of picking up the image can be improved.



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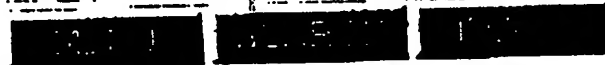
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**(74) Agent:** Shinjiro Arichika, Patent Attorney**(54) Title of the Invention:** Image pickup apparatus using an MRI device**(57) Summary****Problem:** To perform image pickup using an MRI device, while continuously moving the object for imaging.**Configuration:** If the length in the direction of movement of the imageable region of the MRI device 10 is  $M_w$ , the length in the direction of movement of the range for imaging is  $G_w$ , and the time for collection of one image's worth of data is  $M_t$ , then a movement/image pickup simultaneous execution unit 11 controls a belt conveyor 20 so as to effect movement at a speed  $G_v$  equal to or less than  $(M_w - G_w)/M_t$ , and simultaneously executes movement by the belt conveyor 20 and image pickup by the MRI device 10.**Advantageous Result:** The image pickup efficiency can be improved.

## Claims

Claim 1: Image pickup apparatus using an MRI device, comprising an MRI device, and a movement device to move the object for imaging relative to the MRI device, so as to pass through the bore of the MRI device; characterized in comprising a movement/image pickup simultaneous execution unit which, if the length in the direction of movement of the imageable region of said MRI device is  $M_w$ , and the length in the direction of movement of the range for imaging is  $G_w$ , controls said movement device so as to move [the object for imaging] at a speed equal to or less than the quotient  $(M_w - G_w)/M_t$  of the difference of the two  $(M_w - G_w)$  divided by the time  $M_t$  for collection of the data for one image, and further executes image pickup by said MRI device simultaneously with said movement.

Claim 2: The image pickup apparatus using an MRI device according to Claim 1, characterized in comprising excitation region following-movement means which performs movement causing the position of the excitation region for each view to follow the relative movement amount when the plane for image pickup is orthogonal to the direction of relative movement.

Claim 3: Image pickup apparatus using an MRI device according to Claim 1, characterized in comprising phase correction means which performs phase correction of the data for each view according to the amount of relative movement, when the plane for image pickup is parallel to the direction of relative movement.

## Detailed Description of the Invention

0001

### Industrial Field of the Invention

This invention relates to image pickup apparatus using an MRI device, and specifically to an image pickup apparatus which can perform image pickup using the MRI device, while continuously moving the object for imaging.

0002

### Prior Art

An image pickup apparatus comprising an MRI device and a movement device which moves the object for imaging so as to pass through the bore of the MRI device is disclosed in, for example, Japanese Patent Laid-open No. 63-272335. When the plane for image pickup is parallel to the movement direction, this conventional image pickup apparatus first stops movement of the object for imaging G, performs image pickup, and obtains a first image of length T in the movement direction. Then, after moving a distance T, movement is again stopped, image pickup is performed, and a second image is obtained of length T in the movement direction. This is repeated n times, and by joining the n images from the first to the nth, an image of length nT is obtained. Fig. 11 shows a schematic diagram of the above conventional image pickup apparatus. G is the object for imaging (the patient); 60 is a cradle for moving the object for imaging G; 50 is the MRI device; and 50a is the bore. 51 is a movement-stopping control unit which stops the cradle 60 for image pickup, and is part of the MRI device 50.

0003

**Problem to be Solved by the Invention**

In the above conventional image pickup apparatus, the MRI device and movement device do not operate simultaneously. That is, when image pickup is being performed by the MRI device, the movement device is stopped, and during movement by the movement device, the MRI device is stopped. Hence there is the problem that image pickup efficiency is poor. One object of this invention is to provide an image pickup apparatus capable of performing image pickup using the MRI device while continuously moving the object for imaging.

0004

**Means to Solve the Problem**

The image pickup apparatus using an MRI device of this invention is an image pickup apparatus comprising an MRI device and a movement device which moves the object for imaging relative to the MRI device, so as to pass through the bore of the MRI device; characterized in further comprising movement/image pickup simultaneous execution means which, if the length in the movement direction of the imageable region of the above MRI device is  $M_w$ , and the length in the movement direction of the imaging range is  $G_w$ , controls the above movement device such that the movement is at a speed  $G_v$  equal to or less than the difference of these  $(M_w - G_w)$  divided by the time  $M_t$  for collection of the data for one image,  $(M_w - G_w)/M_t$ , and also simultaneously executes image pickup by the above MRI device. It is preferable that the above image pickup apparatus further comprises excitation region following-movement means such that, when the plane for image pickup is orthogonal to the direction of relative movement, movement is performed to cause the position of the excitation region for each view to follow the amount of relative movement. It is preferable that the above image pickup apparatus further comprises phase correction means such that, when the plane of image pickup is parallel to the direction of relative movement, phase correction of the data for each view is performed according to the amount of relative movement.

0005

**Action**

In the image pickup apparatus using an MRI device of this invention, if the length in the movement direction of the imageable region of the MRI device is  $M_w$ , and the length in the movement direction of the imaging range is  $G_w$ , then the movement/image pickup simultaneous execution means controls the movement device such that movement is performed at a speed  $G_v$  less than or equal to the difference of the two  $(M_w - G_w)$  divided by the time  $M_t$  for collection of the data for one image,  $(M_w - G_w)/M_t$ . Further, movement by the movement device and image pickup by the MRI device are executed simultaneously. If the above condition of a speed  $G_v$  is met, one image's worth of data can be collected during the time that the object for imaging is within the imageable region. And if ultra-high speed image pickup is performed by the MRI device with, for example,  $M_t$  within several hundred milliseconds, then even with the speed  $G_v$  at a practical speed there is little movement of the object for imaging, so that there is little

blurring and few spurious images, called motion artifacts, and image quality is not greatly degraded. Hence image pickup can be performed while continuously moving the object for imaging, without performing special correction, so that the image pickup efficiency can be improved.

0006

When comprising excitation region following-movement means, and when the plane for image pickup is orthogonal to the direction of relative movement, if the position of the excitation region for each view is moved to follow the amount of relative movement by this excitation region following-movement means, [the effect] is equivalent to the case where the object for imaging is stationary, and no motion artifacts occur. Hence image pickup with high image quality is possible while continuously moving the object for imaging.

0007

When comprising phase correction means, and when the plane for image pickup is parallel to the direction of relative movement, if the data for each view is phase-corrected according to the amount of relative movement by the phase correction means, [the effect] is equivalent to the case where the object for imaging is stationary, and no motion artifacts occur. Hence image pickup with high image quality is possible while continuously moving the object for imaging.

0008

### **Embodiments**

Below, this invention is explained in further detail based on the embodiments shown in the drawings. The [embodiments] do not limit the scope of this invention. Fig. 1 is a schematic diagram of an image pickup apparatus 1 using an MRI device of one embodiment of this invention. G is the object for imaging (not limited to a patient); 20 is a movement device, such as a conveyor belt, which continuously moves the object for imaging G; 10 is the MRI device; and 10a is the bore. The MRI device 10 comprises a movement/image pickup simultaneous execution unit 11; a correction requirement judgment unit 12; an axial view-linked slice movement unit 13; a sagittal/coronal SAT application unit 14; a sagittal/coronal phase correction unit 15; and an oblique/three-dimensional integrated control unit 16.

0009

As shown in Fig. 2, the movement/image pickup simultaneous execution unit 11 controls the belt conveyor 20 to move the object for imaging G at a movement speed  $G_v$ . Simultaneously, image pickup is started with repetition time  $TR$  (11A). If the length in the movement direction of the imageable region of the MRI device 10 is  $M_w$ , and the length in the movement direction of the imaging range is  $G_w$ , then when the time to collect one image's worth of data is  $M_t$ ,

$$G_v \leq (M_w - G_w) / M_t$$

As a result, one image's worth of data can be collected during the time when the object for imaging G is in the imageable region  $M_w$ . Fig. 3 shows a schematic diagram of the

case of the maximum condition  $G_v = (M_w - G_w)/M_t$ . In general, when one image's worth of data consists of  $M$  views,

$$TR = M_t/M$$

0010

As shown in Fig. 4, the correction requirement judgment unit 12 first judges whether the movement distance  $G_v \cdot M_t$  during the time for collection of one image's worth of data is sufficiently small (12A). If it is sufficiently small that motion artifacts can be ignored, corrections are judged to be not necessary, and control is returned to the system (EXIT1) without starting the axial view-linked slice movement unit 13, the sagittal/coronal SAT application unit 14, the sagittal/coronal phase correction unit 15, or the oblique/three-dimensional integrated control unit 16. When control is returned via EXIT1, the system reconstructs the image from the collected data. If [the distance] is not sufficiently small, a judgment is made as to whether the image pickup is of an axial image with the imaging plane orthogonal to the direction of relative movement (12B). If axial, the axial view-linked slice movement unit 13 is started (12C). If not axial, a judgment is made as to whether the image pickup is of a sagittal image or a coronal image with the imaging plane parallel to the direction of relative movement (12D). If sagittal or coronal, the sagittal/coronal SAT application unit 14 and sagittal/coronal phase correction unit 15 are started (12E). If neither sagittal nor coronal, a judgment is made as to whether the image pickup is oblique, with the imaging plane inclined with respect to the direction of relative movement, or three-dimensional (12F). If oblique or three-dimensional, the oblique/three-dimensional integrated control unit 16 is started (12G). If neither oblique nor three-dimensional, control is returned to the system (EXIT2) without starting the axial view-linked slice movement unit 13, the sagittal/coronal SAT application unit 14, the sagittal/coronal phase correction unit 15, or the oblique/three-dimensional integrated control unit 16. When control is returned via EXIT2, the system performs error processing.

0011

As shown in Fig. 5, the axial view-linked slice movement unit 13 moves the position of RF excitation/inversion to follow movement of the object for imaging  $G$  for each view, and collects data for each view (13A). This axial view-linked slice movement unit 13 is equivalent to excitation region following-movement means. As shown in Fig. 6, the object for imaging  $G$  moves by an amount  $G_v \cdot TR$  between views, so that if the RF excitation region  $M_s$  also moves by  $G_v \cdot TR$ , [the effect] is equivalent to the case in which the object for imaging  $G$  is stationary. Hence image pickup with high image quality while continuously moving the object for imaging  $G$  is possible, without the occurrence of motion artifacts. Movement of the RF excitation region  $M_s$  is specifically achieved by, for example, changing the RF frequency for each view.

0012

As shown in Fig. 7, the sagittal/coronal SAT application unit 14 adds a spatial SAT pulse, as necessary, prior to the normal pulse sequence, to limit the region of appearance of MR signals according to the position of the object for imaging  $G$  for each view. Then, data is

collected for each view (14A). As shown in Fig. 8, the object for imaging G moves through the RF excitation region Ms. Because of this, even MR signals from the same location of the object for imaging G are phase-shifted for each view along whichever of the frequency-axis and the phase-axis direction coincides with the direction of movement. The sagittal/coronal phase correction unit 15 therefore multiplies the data D'(f,p) for each view by either

$\exp(-j2\pi f\Delta x/F_w)$ , where f is the data number in the frequency-axis direction, and is an integer from  $(-N/2)+1$  to  $N/2$ ,  $\Delta x$  is the phase shift amount from the gradient center, and  $F_w$  is the imageable region in the frequency-axis direction, or by

$\exp(-j2\pi p\Delta y/P_w)$ , where p is the data number in the phase-axis direction, and is an integer from  $(-M/2)+1$  to  $M/2$ ,  $\Delta y$  is the phase shift amount from the gradient center, and  $P_w$  is the imageable region in the phase-axis direction. The result is taken to be the view data D(f,p) (15A).

0013

Next, the principle of the above phase correction is explained. As shown in Fig. 9, if the case of movement in the frequency-axis direction is assumed, then the MR signals D(f,p) from a signal source g(x,y) in real space are expressed as in eq. (1).

0014

[equation 1]

$$D(f,p) = \int_{-\frac{M}{2}}^{\frac{M}{2}} \int_{-\frac{N}{2}}^{\frac{N}{2}} g(x,y) e^{-j\frac{2\pi}{F_w}fx} e^{-j\frac{2\pi}{P_w}py} dx dy$$

0015

If the x-coordinate of the gradient center is  $x'$ , and the shift in position from the gradient center is  $\Delta x$ , then  $x = \Delta x + x'$ , so that eq. (2) is obtained.

0016

[equation 2]

$$\begin{aligned} D(f,p) &= \int_{-\frac{M}{2}}^{\frac{M}{2}} \int_{-\frac{N}{2}-\Delta x}^{\frac{N}{2}-\Delta x} g(\Delta x+x',y) e^{-j\frac{2\pi}{F_w}fx'} e^{-j\frac{2\pi}{P_w}py} dy e^{-j\frac{2\pi}{F_w}f\Delta x} \\ &= e^{-j\frac{2\pi}{F_w}f\Delta x} \int_{-\frac{M}{2}}^{\frac{M}{2}} \int_{-\frac{N}{2}-\Delta x}^{\frac{N}{2}-\Delta x} g(\Delta x+x',y) e^{-j\frac{2\pi}{F_w}fx'} e^{-j\frac{2\pi}{P_w}py} dy \\ &= e^{-j\frac{2\pi}{F_w}f\Delta x} D'(f,p) \end{aligned}$$



0017

Hence it is sufficient to perform the above phase correction, proportional to  $f\Delta x$ , on the echo data  $D'(f,p)$  measured at a position shifted by  $\Delta x$  from the gradient center. The case of movement in the phase-axis direction is similar; it is sufficient to perform the above phase correction, proportional to  $p\Delta y$ , on the echo data  $D'(f,p)$  measured at a position shifted  $\Delta y$  from the gradient center. Even if the order of phase encoding is not in the order of magnitude, corrections at each position are performed according to the position shifts  $\Delta x$ ,  $\Delta y$ , so no problem arises. If the object for imaging G is only shifted by a fixed distance, linear phase correction is sufficient, and shifting after reconstruction is adequate; but in this method, the position of the object for imaging shifts with each phase encoding, so that square phase correction is used, and correction after reconstruction is not possible.

0018

As shown in Fig. 10, the oblique/three-dimensional integrated control unit 16 determines the tasks to be performed by the axial view-linked slice movement unit 13 and the sagittal/coronal SAT application unit 14, starts each of these, and collects data  $D'(f,p)$  (16A). That is, RF excitation/inversion is performed similarly to the case of axial views, spatial saturation pulse application is performed similarly to the case of sagittal/coronal views, and data  $D'(f,p)$  is collected. Next, for oblique imaging, the oblique/three-dimensional integrated control unit 16 divides the movement of the object for imaging G into components in the frequency-axis direction and in the phase-axis direction, and each is phase-corrected by the sagittal/coronal phase correction unit 15 to obtain data  $D(f,p)$ . For three-dimensional imaging, [the oblique/three-dimensional integrated control unit 16] divides the movement of the object for imaging G into components in one frequency-axis direction and two phase-axis direction, and each is phase-corrected by the sagittal/coronal phase correction unit 15 to obtain data  $D(f,p)$ . Then, control is returned to the system. For oblique imaging, the system takes the two-dimensional Fourier transform and reconstructs the image. For three-dimensional imaging, [the system] takes the three-dimensional Fourier transform and reconstructs the image.

0019

As is clear from the above explanation, by means of the image pickup device of the above embodiment, image pickup of axial images, sagittal images, coronal images, oblique images, or three-dimensional images can be performed by the MRI device 10, while continuously moving the object for imaging G. If the equipment is a specialized apparatus for image pickup only of axial images, the bore 10a may be made extremely short.

0020

Image pickup methods which do not use Fourier transforms, such as spiral scan and filtered back-projection methods, can be accommodated by changing the RF frequency for each view with respect to the imaging plane [Tr's note: It is not clear what relation the imaging plane has to the method used.], and in readout using a gradient magnetic field, by performing the above phase correction for each data point according to the readout direction (in the direction of the straight line from the origin in k-space to the echo data

point). In cases where the movement speed  $G_v$  is fast, or the echo time  $TE$  is long, it is preferable that "gradient moment nulling" or other movement correction be performed for axes having components in the movement direction. Even in the case of ultra-fast image pickup methods, when multishot methods are used in which RF excitation is applied separately a number of times, it is preferable that the correction of this invention be applied for each shot.

0021

### **Advantageous Result of the Invention**

By means of the image pickup apparatus using an MRI device of this invention, image pickup can be performed using the MRI device while continuously moving the object for imaging. Hence the efficiency of image pickup can be improved.

### **Brief Description of the Drawings**

Fig. 1 Schematic diagram of one embodiment of the image pickup apparatus using an MRI device of this invention

Fig. 2 Flowchart of the operation of the movement/image pickup simultaneous execution unit

Fig. 3 Explanatory diagram of the relation between the imageable region, data collection time, and movement speed

Fig. 4 Flowchart of the operation of the correction requirement judgment unit

Fig. 5 Flowchart of the operation of the axial view-linked slice movement unit

Fig. 6 Explanatory diagram of movement of a slice in axial imaging

Fig. 7 Flowchart of the operation of the sagittal/coronal SA[T] application unit and sagittal/coronal phase correction unit

Fig. 8 Explanatory diagram of movement of the object for imaging during sagittal/coronal imaging

Fig. 9 Diagram explaining the principle of phase correction in sagittal/coronal imaging

Fig. 10 Flowchart of the operation of the oblique/three-dimensional integrated control unit

Fig. 11 Schematic diagram of one example of a conventional image pickup apparatus using an MRI device

### **Explanation of Symbols**

- 1 Image pickup apparatus using MRI device
- 10 MRI device
- 10a Bore
- 11 Movement/image pickup simultaneous execution unit
- 12 Correction requirement judgment unit

13	Axial view-linked slice movement unit
14	Sagittal/coronal SA[T] application unit
15	Sagittal/coronal phase correction unit
16	Oblique/three-dimensional integrated control unit
20	Belt conveyor
G	Object for imaging
Mw	Imageable region
Gw	Range for imaging
Mt	Time for collection of one image's worth of data
Gv	Movement speed
TR	Repetition time
Ms	Slice

Figure 1

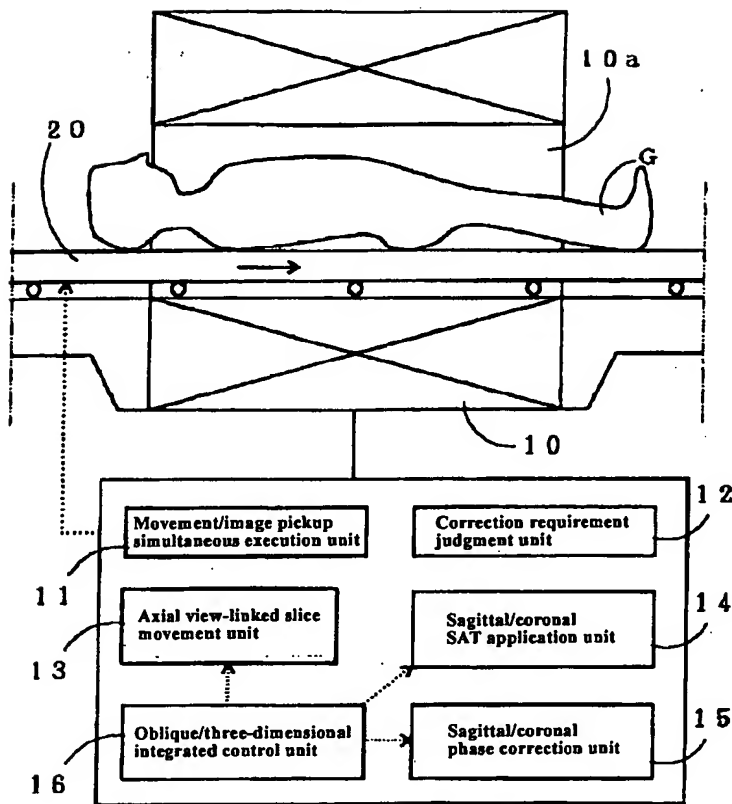


Figure 3

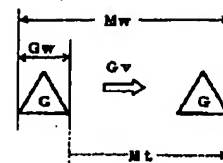


Figure 6

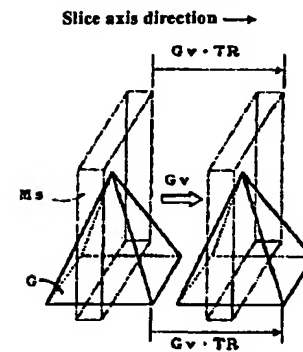


Figure 2

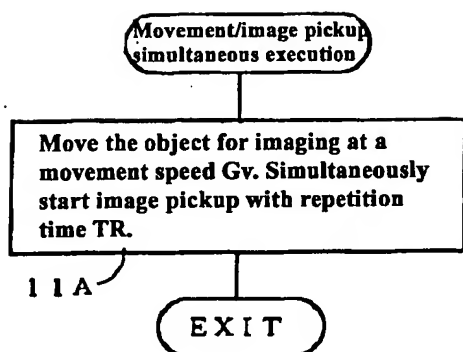


Figure 5

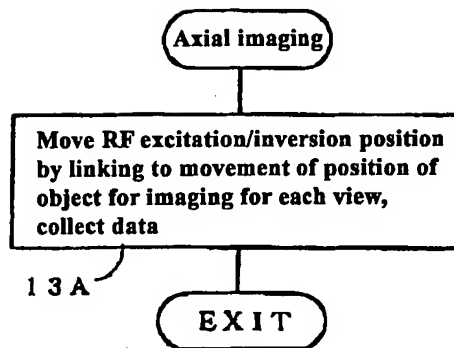


Figure 4

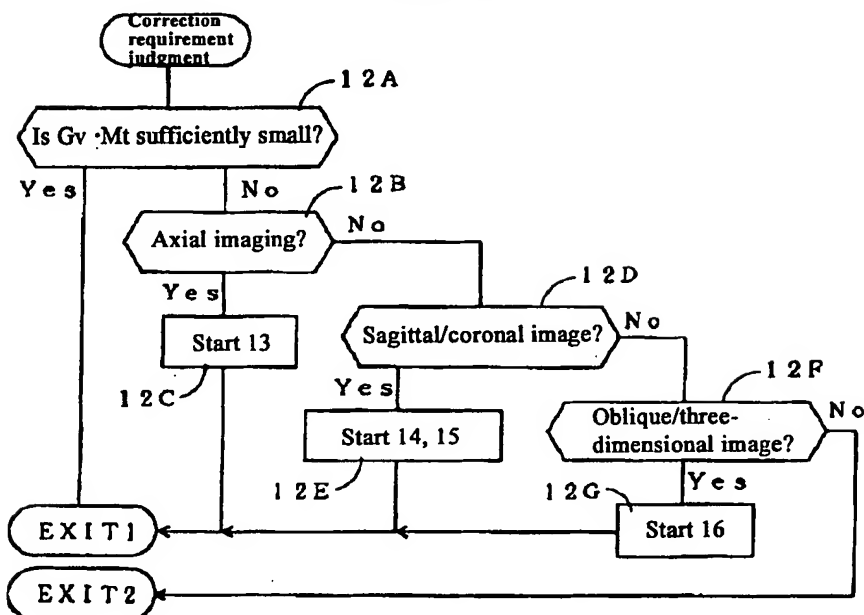


Figure 8

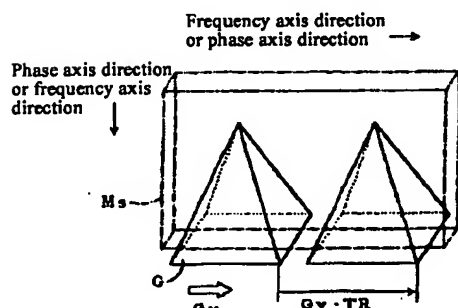


Figure 7

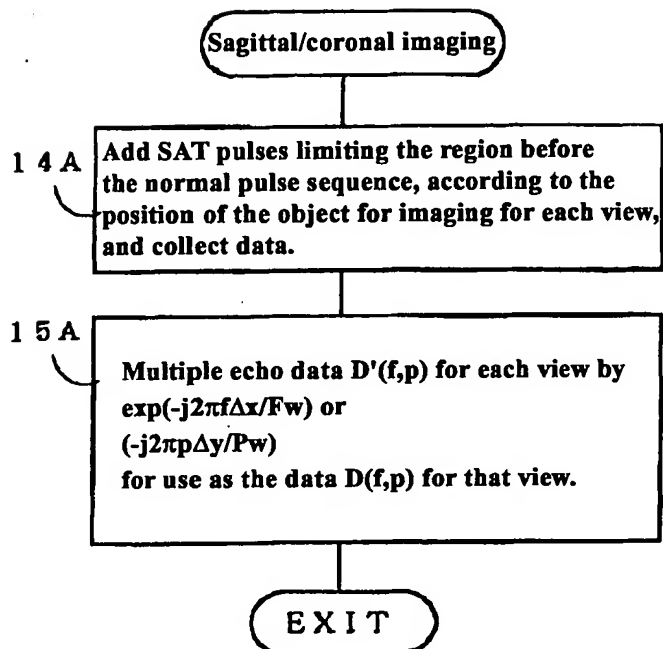


Figure 9

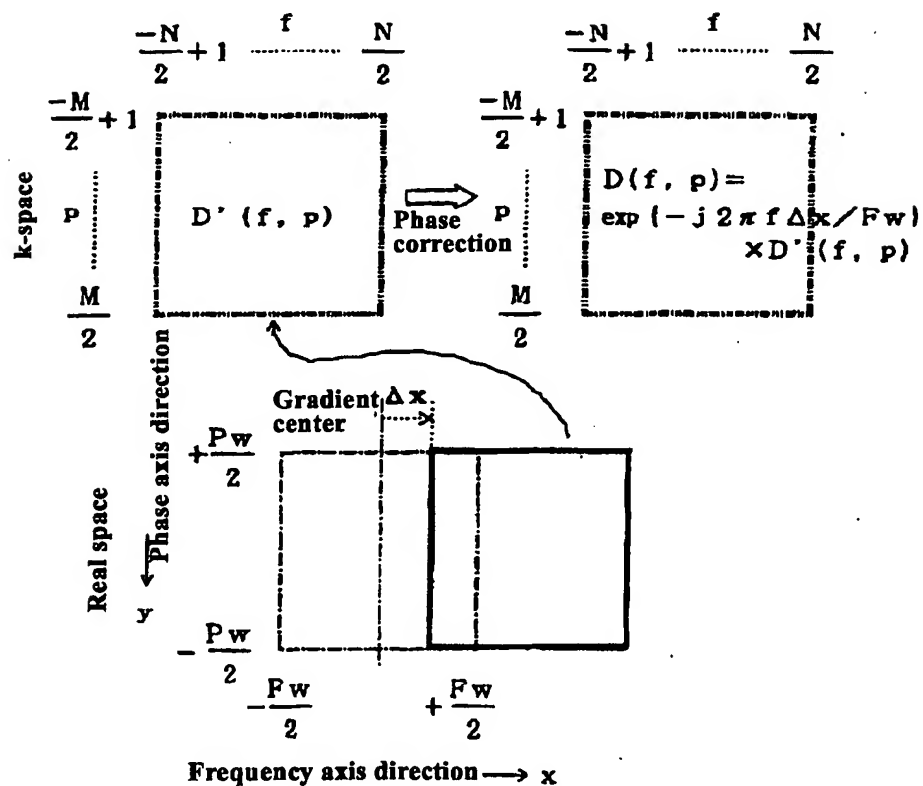


Figure 10

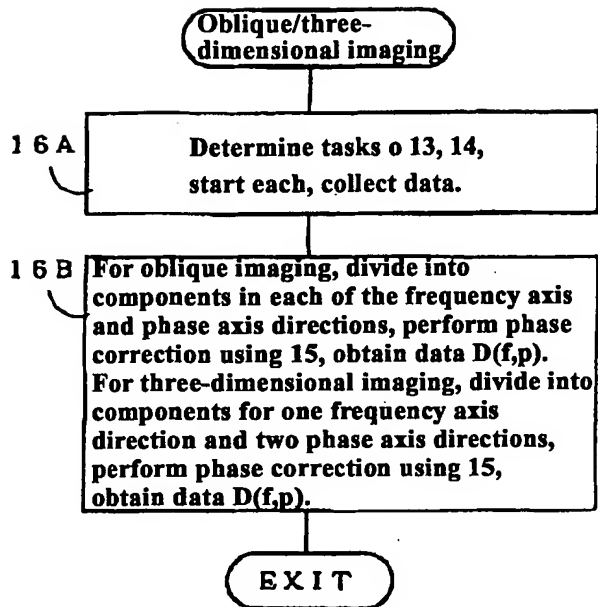


Figure 11

